The listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

1. (Original)   A vehicle surroundings monitoring apparatus, comprising:

frontal information detecting means for detecting at least solid object information and traveling road information in front of an own vehicle;

preceding vehicle trace calculating means for calculating a trace of a preceding vehicle from past data of said preceding vehicle;

first own traveling path calculating means for calculating a first traveling path of said own vehicle based on said traveling road information;

second own traveling path calculating means for calculating a second traveling path of said own vehicle based on said trace of said preceding vehicle; and

final own traveling path calculating means for calculating a final traveling path of said own vehicle based on said first traveling path and said second traveling path;

2. (Original)   A vehicle surroundings monitoring apparatus, comprising:

frontal information detecting means for detecting at least solid object information and traveling road information in front of an own vehicle;

first own traveling path calculating means for calculating a first traveling path of said own vehicle based on said traveling road information;

third own traveling path calculating means for calculating a third traveling path of an own vehicle based on traveling conditions of said own vehicle; and

final own traveling path calculating means for calculating a final traveling path of said own vehicle based on said first traveling path and said third traveling path;

3. (Original)   A vehicle surroundings monitoring apparatus, comprising:

frontal information detecting means for detecting at least solid object information and traveling road information in front of an own vehicle;

preceding vehicle trace calculating means for calculating a trace of a preceding vehicle from past data of said preceding vehicle;

first own traveling path calculating means for calculating a first traveling path of said own vehicle based on said traveling road information;

second own traveling path calculating means for calculating a second traveling path of said own vehicle based on said trace of said preceding vehicle;

third own traveling path calculating means for calculating a third traveling path of said own vehicle based on traveling conditions of said own vehicle; and

final own traveling path calculating means for calculating a final traveling path of said own vehicle based on said first traveling path, said second traveling path and said third traveling path.

4. (Original)   A vehicle surroundings monitoring apparatus, comprising:

frontal information detecting means for detecting at least solid object information and traveling road information in front of an own vehicle;

preceding vehicle trace calculating means for calculating a trace of a preceding vehicle from past data of said preceding vehicle;

first own traveling path calculating means for calculating a first traveling path of said own vehicle based on said traveling road information;

second own traveling path calculating means for calculating a second traveling path of said own vehicle based on said trace of said preceding vehicle;

third own traveling path calculating means for calculating a third traveling path of said own vehicle based on traveling conditions of said own vehicle;

fourth own traveling path calculating means for calculating a fourth traveling path of said own vehicle based on said first own traveling path and said third own traveling path; and

final own traveling path calculating means for calculating a final traveling path of said own vehicle based on said fourth traveling path and said second traveling path when a preestablished condition is satisfied.

5. (Original)   The vehicle surroundings monitoring apparatus according to claim 4, wherein said preestablished condition is that the preceding vehicle exists and there is no possibility of evacuation of said preceding vehicle and said own vehicle does not make a turn.

6. (Original)   The vehicle surroundings monitoring apparatus according to claim 2, wherein said traveling conditions include at least a yaw rate of said own vehicle.

7. (Original)   The vehicle surroundings monitoring apparatus according to claim 3, wherein said traveling conditions include at least a yaw rate of said own vehicle.

8. (Original)   The vehicle surroundings monitoring apparatus according to claim 4, wherein said traveling conditions include at least a yaw rate of said own vehicle.

9. (Original)   The vehicle surroundings monitoring apparatus according to claim 1, wherein said final own traveling path is calculated from a previous own traveling path and a present own traveling path.

10. (Original) The vehicle surroundings monitoring apparatus according to claim 2, wherein said final own traveling path is calculated from a previous own traveling path and a present own traveling path.

11. (Original) The vehicle surroundings monitoring apparatus according to claim 3, wherein said final own traveling path is calculated from a previous own traveling path and a present own traveling path.

12. (Original) The vehicle surroundings monitoring apparatus according to claim 4, wherein said final own traveling path is calculated from a previous own traveling path and a present own traveling path.

13. (Original) The vehicle surroundings monitoring apparatus according to claim 1, wherein said final own traveling path is calculated based on respectively weighted own traveling paths.

14. (Original) The vehicle surroundings monitoring apparatus according to claim 2, wherein said final own traveling path is calculated based on respectively weighted own traveling paths.

15. (Original) The vehicle surroundings monitoring apparatus according to claim 3, wherein said final own traveling path is calculated based on respectively weighted own traveling paths.

16. (Original) The vehicle surroundings monitoring apparatus according to claim 4, wherein said final own traveling path is calculated based on respectively weighted own traveling paths.

17. (Original) The vehicle surroundings monitoring apparatus according to claim 1, wherein when other own traveling paths are calculated using said second own traveling path, said second own traveling path is effectively used only in the vicinity of said preceding vehicle.

18. (Currently amended) A traveling control system for controlling a traveling of an own vehicle at least based on said final own traveling path calculated by said vehicle surroundings monitoring apparatus described in claim 1 claims 1.

19. (Currently amended) A traveling control system for controlling a traveling of an own vehicle at least based on said final own traveling path calculated by said vehicle surroundings monitoring apparatus described in claim 2 claims 2.

20. (Currently amended) A traveling control system for controlling a traveling of an own vehicle at least based on said final own traveling path calculated by said vehicle surroundings monitoring apparatus described in claim 3 claims 3.

21. (Currently amended) A traveling control system for controlling a traveling of an own vehicle at least based on said final own traveling path calculated by said vehicle surroundings monitoring apparatus described in <u>claim 4</u> ~~claims 4~~.